AMENDMENTS TO THE SPECIFICATION

Page 1, 1ˢᵗ paragraph:

This application is based on Application No. 2000-363014, filed in Japan on November

11, 2000, the contents of which are hereby incorporated by reference. This application is also a
, now US Patent No. 6,631,324

divisional of parent Application No. 09/870,795 filed June 1, 2001, the disclosure of which is

incorporated herein by reference.

Page 11, please delete the last full paragraph

Paragraph bridging pages 11 and 12:

Fig. 9(b)9 is a flow chart for explaining the details of the "vehicle tracking processing"

according to the present invention.

Page 12, please delete the 1ˢᵗ full paragraph

Page 11, 2ⁿᵈ full paragraph:

Fig. 10(b)10 is a flow chart for explaining the details of the "moving vehicle detection

processing" according to the present invention.

Paragraph bridging page 23 and page 24:

In step 606, the distance image obtained in steps 603 through 605 is projected to the X

axis to form a histogram Xproj (m), as illustrated in Fig. 13. As the histogram is prepared in this

manner, when the laser radar 100 is detectingddetecting a side wall on a straight line road for

instance, the detection points data, detecting the side wall, become a group of detection points

arranged in the longitudinal direction, and hence, when seeing the distance image corresponding

to the group of detection points in a histogram in which the distance image is projected to the X

axis, a peak comes out at a side or lateral position X in which the side wall exists. Then, in